

Abstract

A method and a device for detecting road users and obstacles on the basis of camera images, in order to determine their distance from the observer and to classify them. In a two-step classification, potential other parties involved in a collision are detected and identified. In so doing, in a first step, potential other parties involved in a collision are marked in the image data of a mono-image camera; their distance and relative velocity are subsequently determined so that endangering objects can be selectively subjected to a type classification in real time. By breaking down the detection activity into a plurality of steps, the real-time capability of the system is also rendered possible using conventional sensors already present in the vehicle.

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